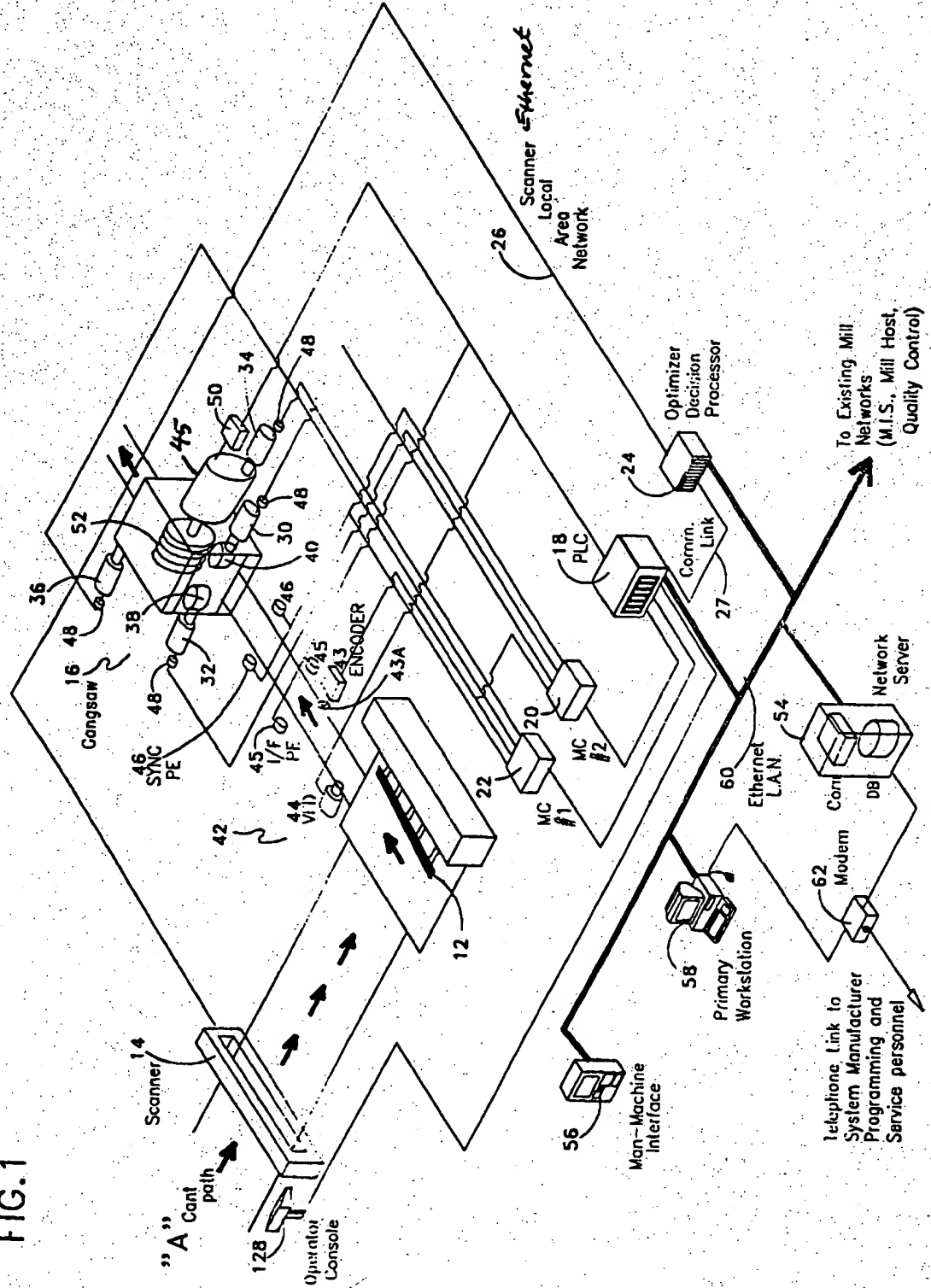


FIG. 1



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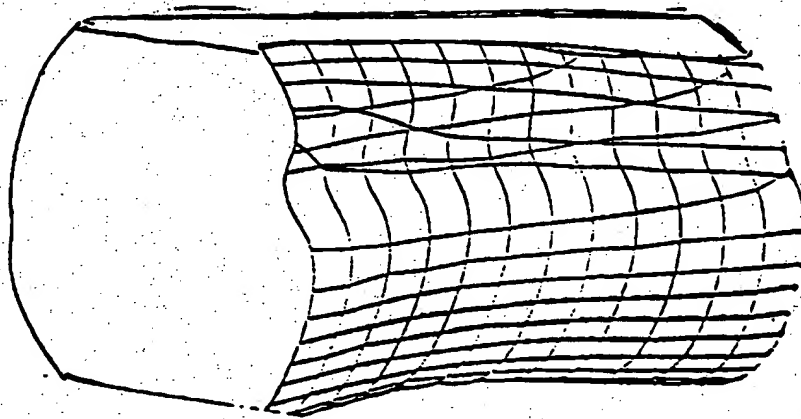
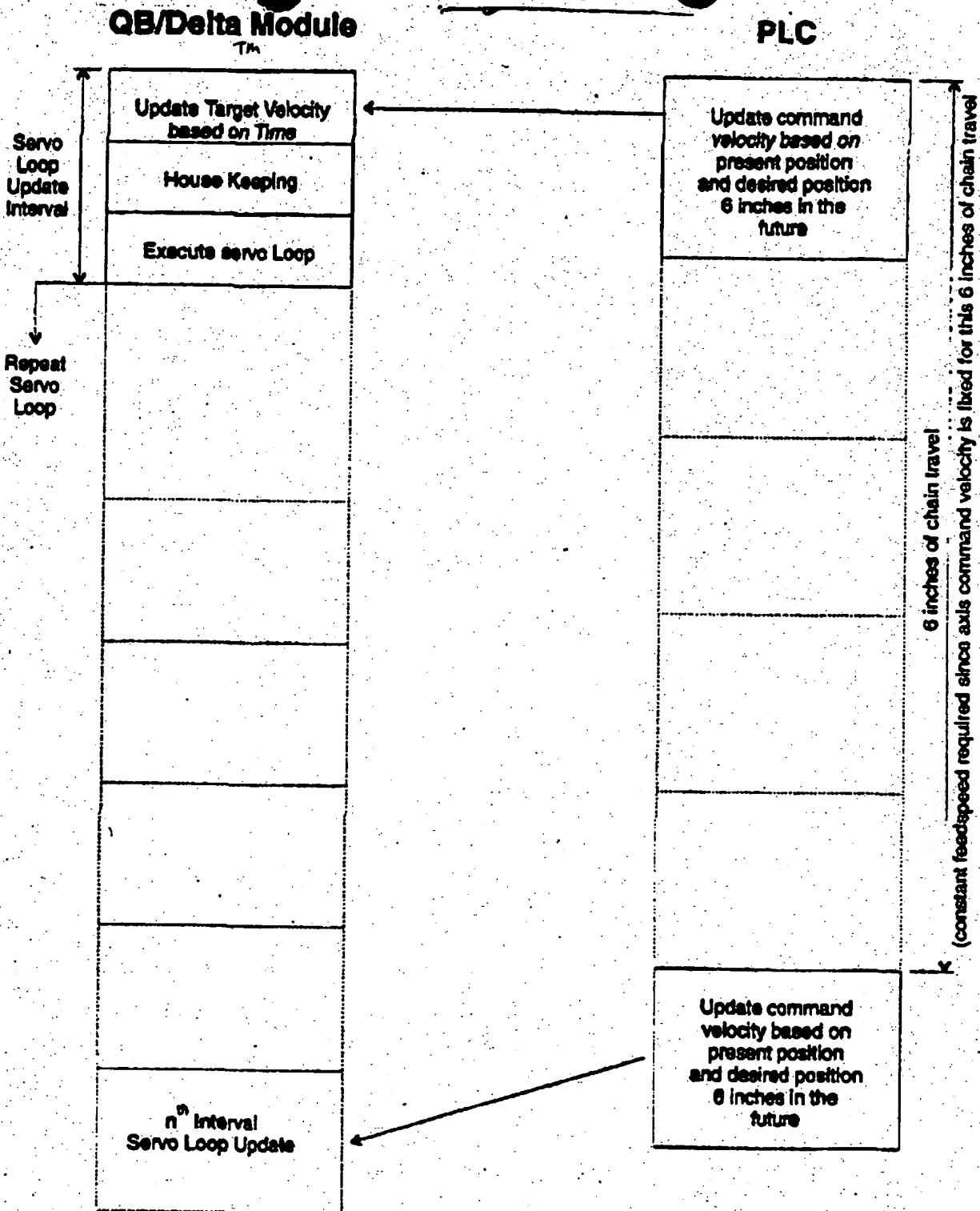


FIG. 1a

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NOTE: This drawing depicts functionality only.

This is not an exact representation of the task divisions within the motion controller

FIG. 2

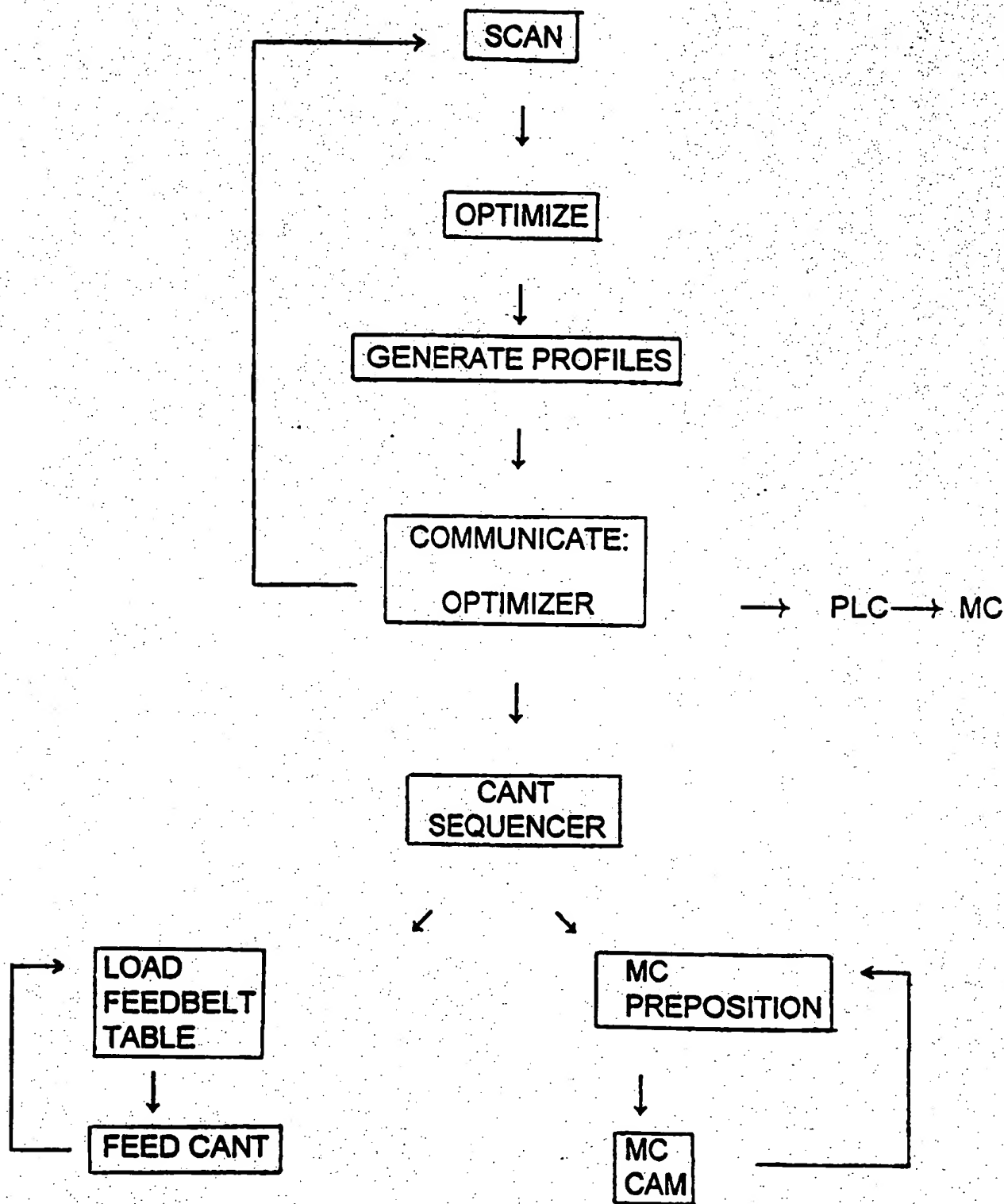


FIG. 3

Original Points

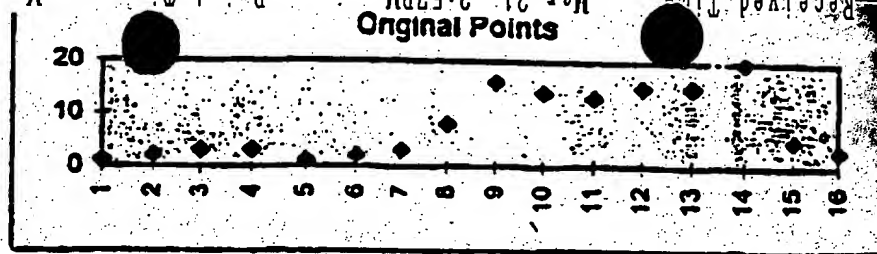


FIG. 4a

1. Generate Polynomial

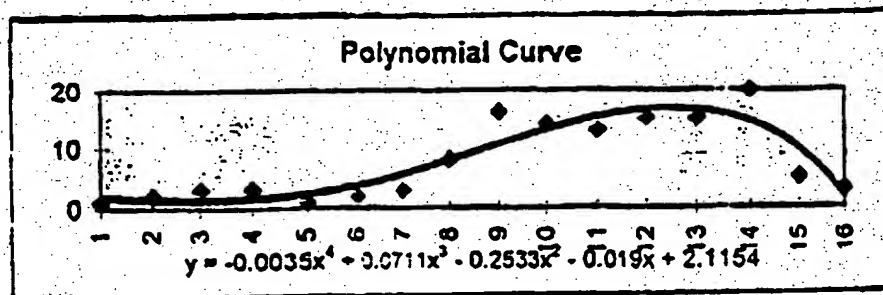


FIG. 4b

2. Calculate discrete points

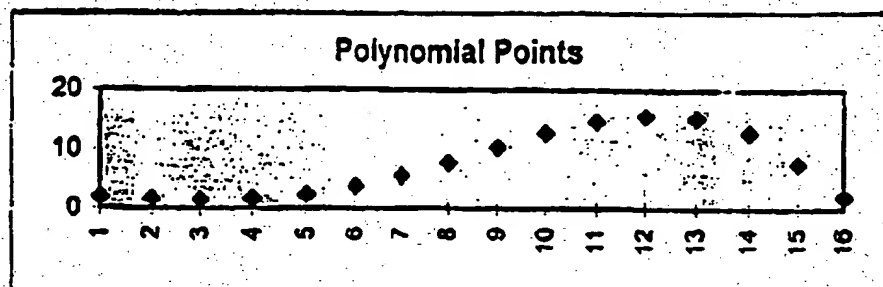


FIG. 4c

3. Apply machine constraints

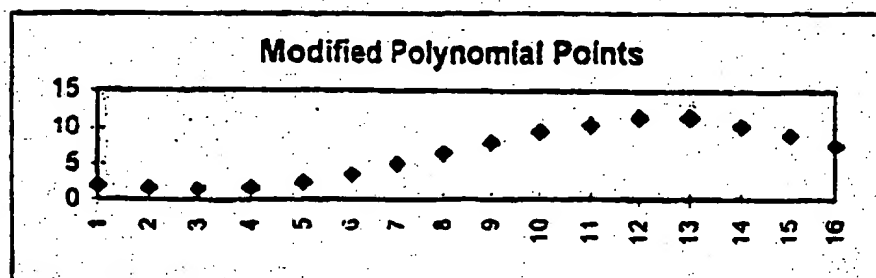


FIG. 4d

4. Re-generate polynomial

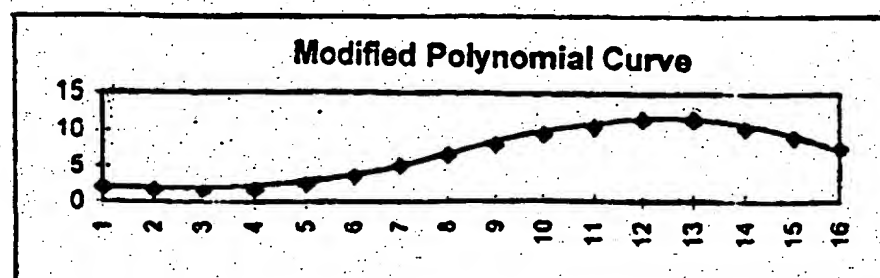
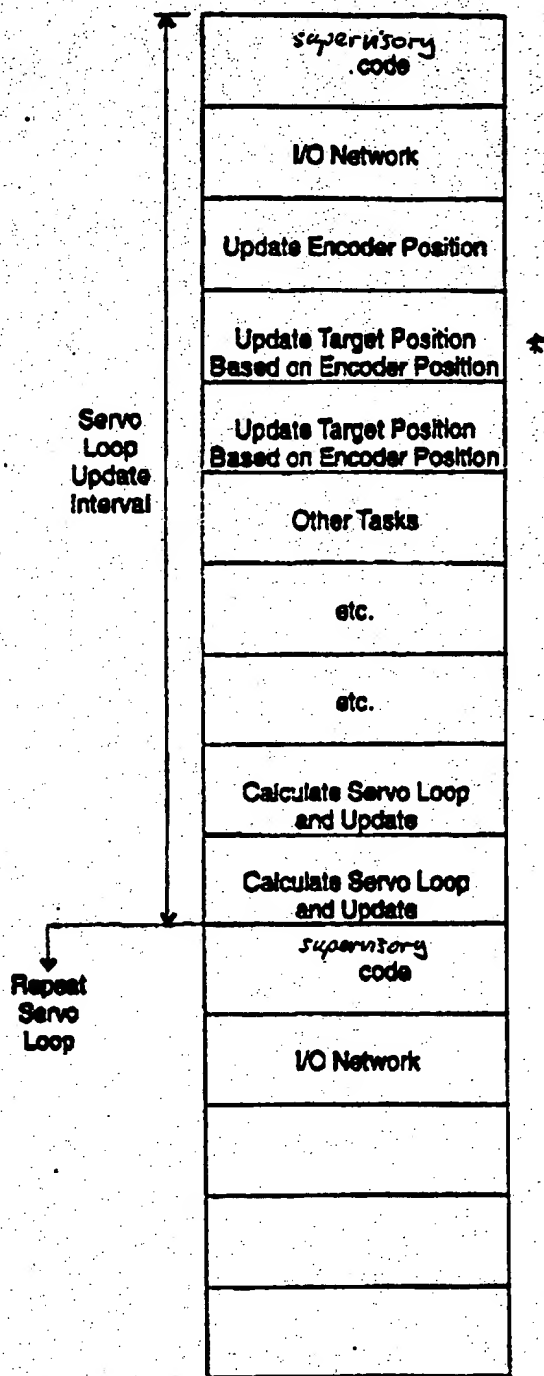


FIG. 4e

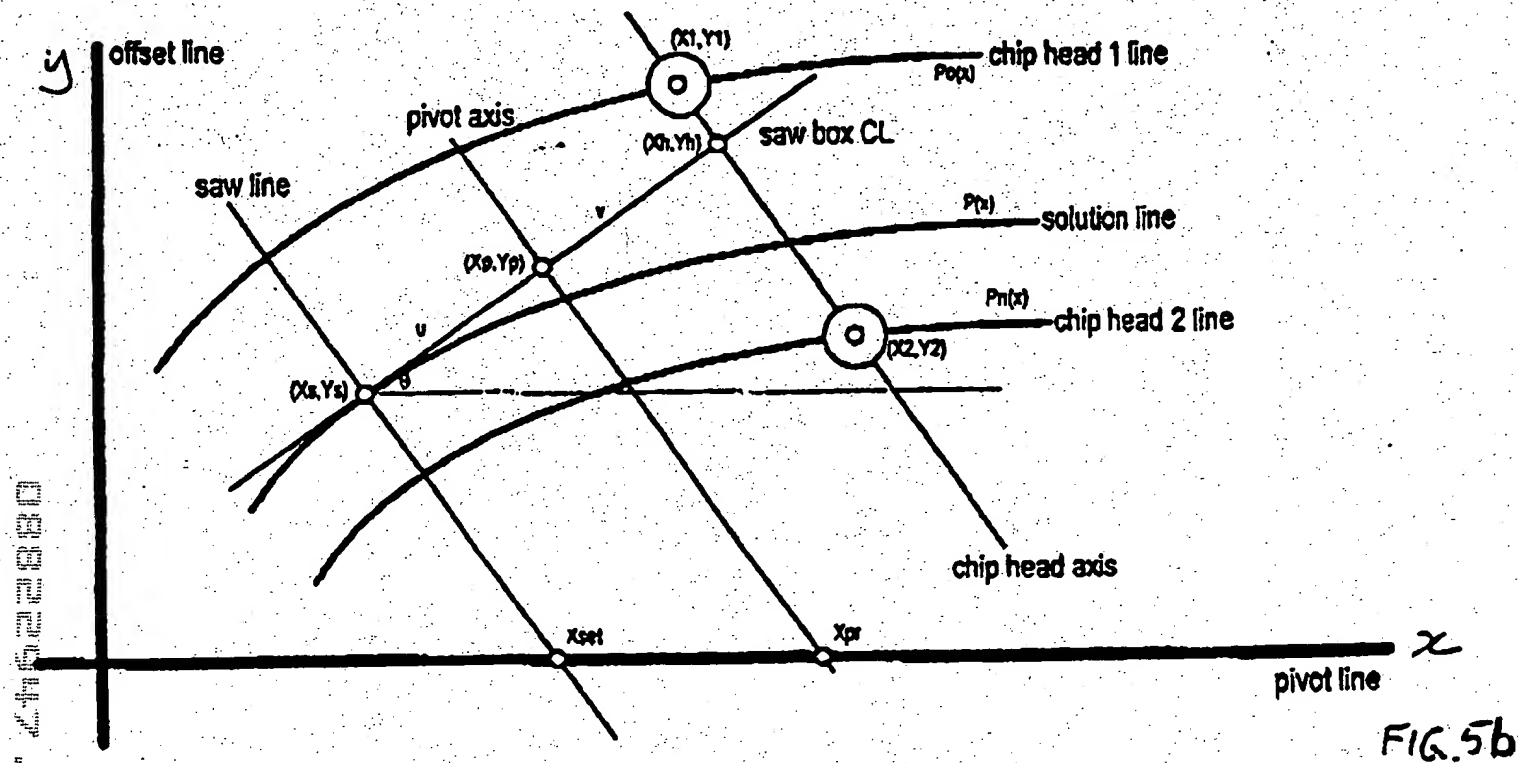
# MC Motion Control



NOTE: This drawing depicts functionality only.

This is not an exact representation  
of the task divisions within the motion  
controller

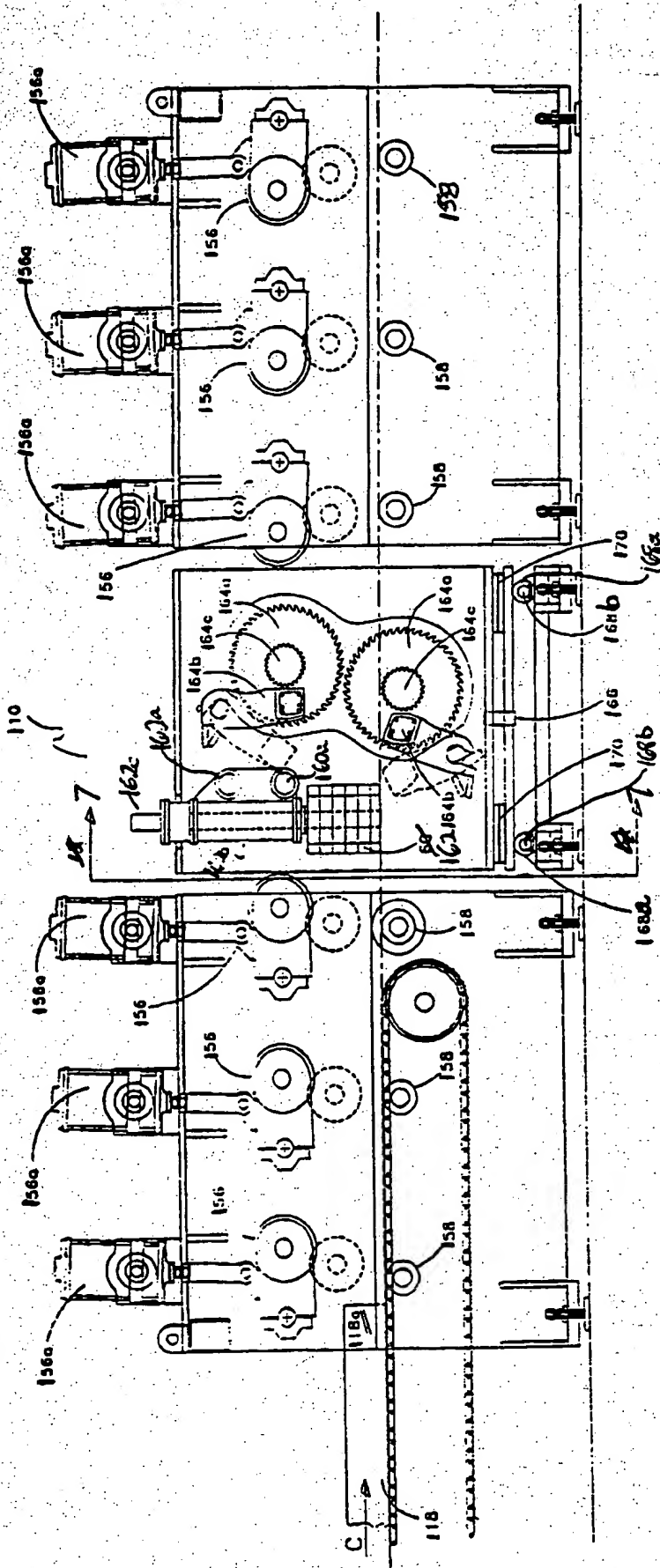
FIG 5a



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462280" 4622830

FIG. 6



Mar. 21, 1980 3:26PM

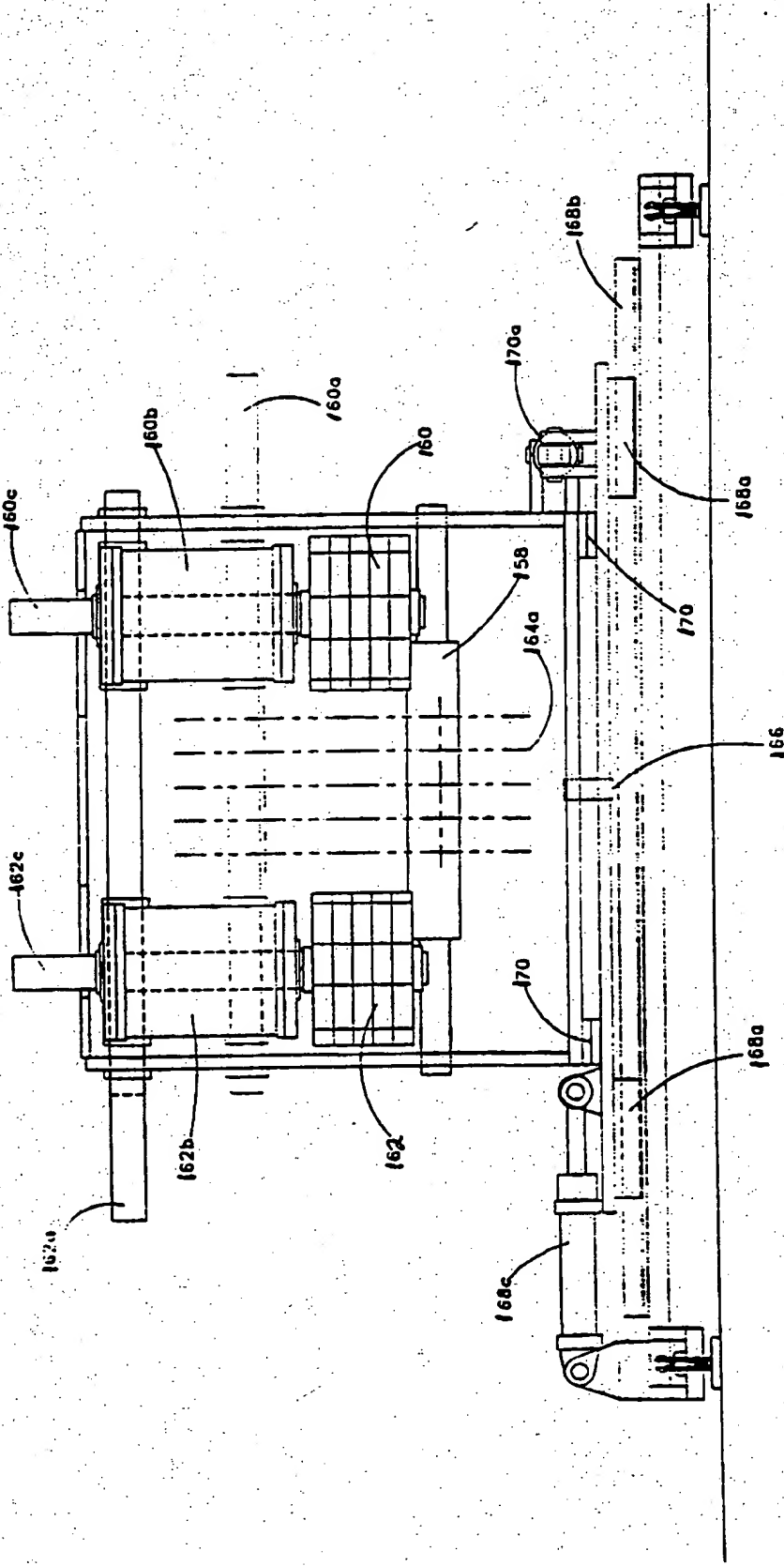
Print Time

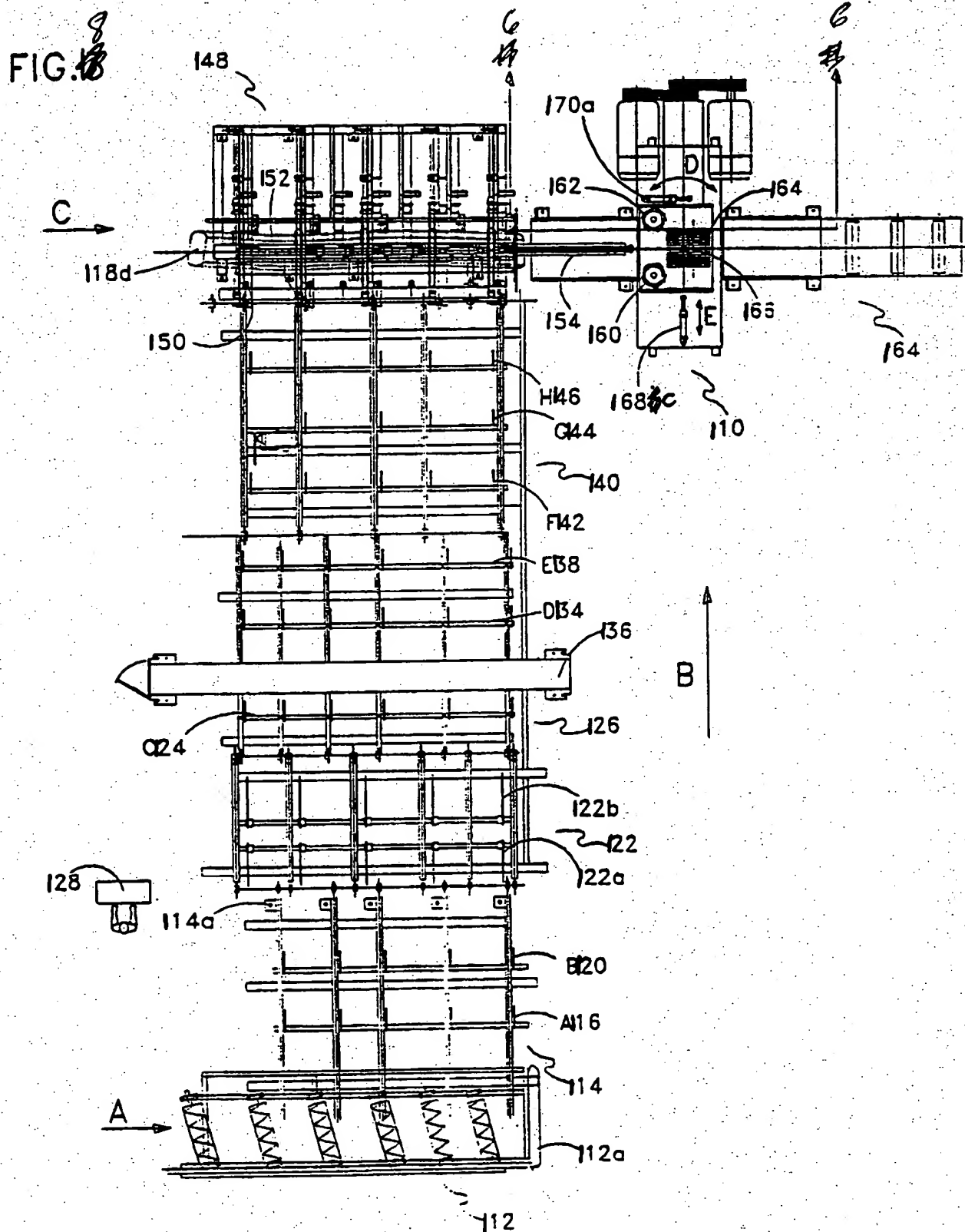
Mar. 21, 2:57PM

Received Time

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FIG. 14

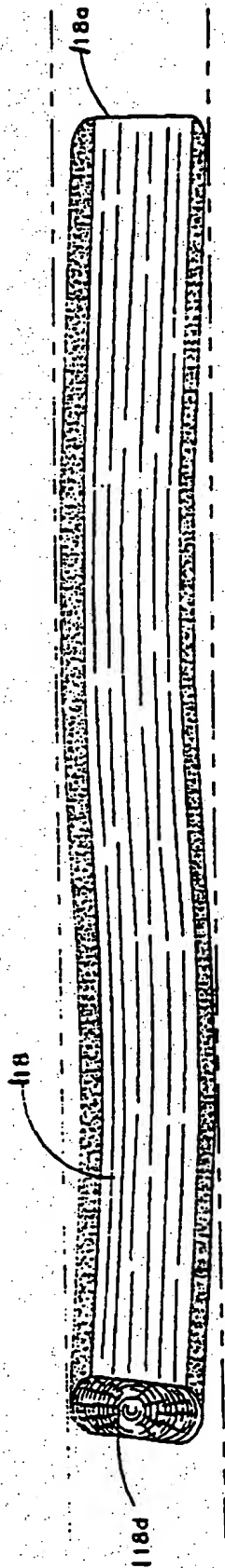
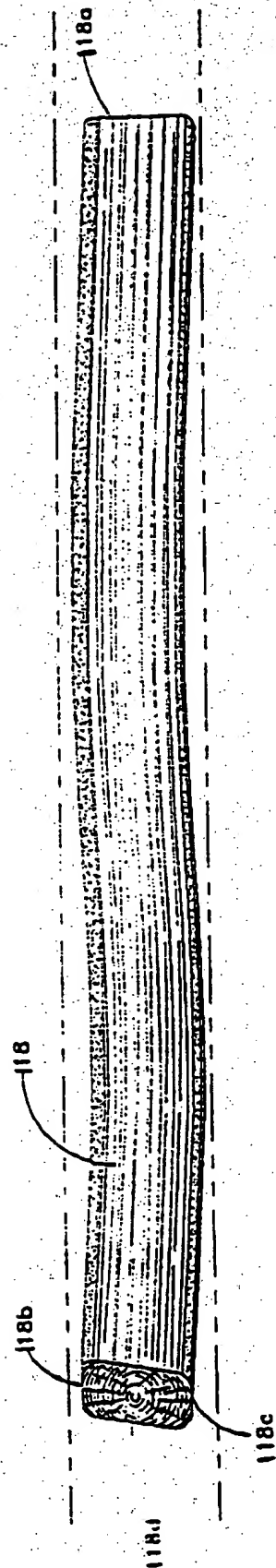


FIG. 14a



Mar. 21. 3:25PM

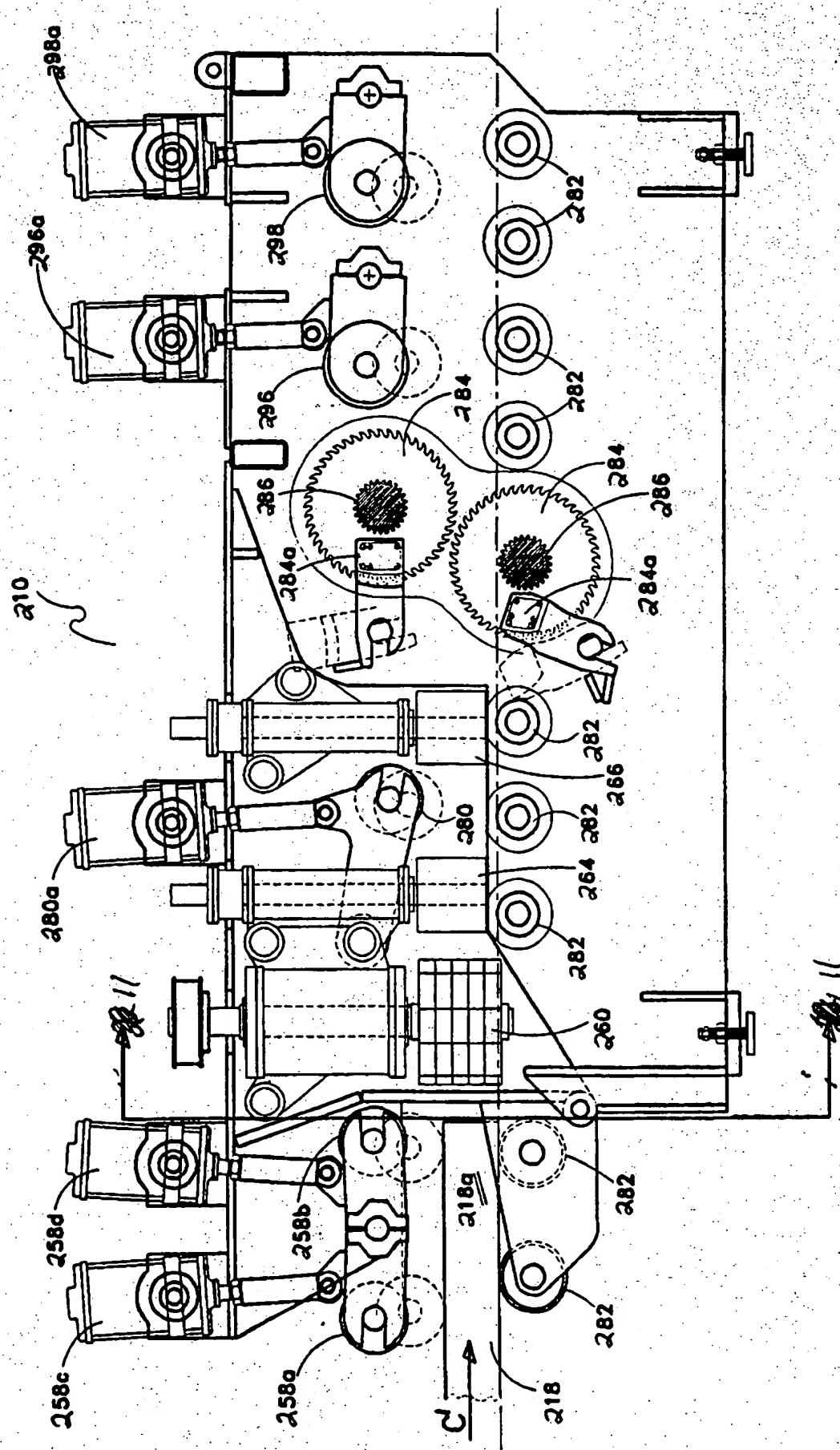
Print Time

Mar. 21. 2:57PM

Received Time

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FIG. 28



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FIG. 21

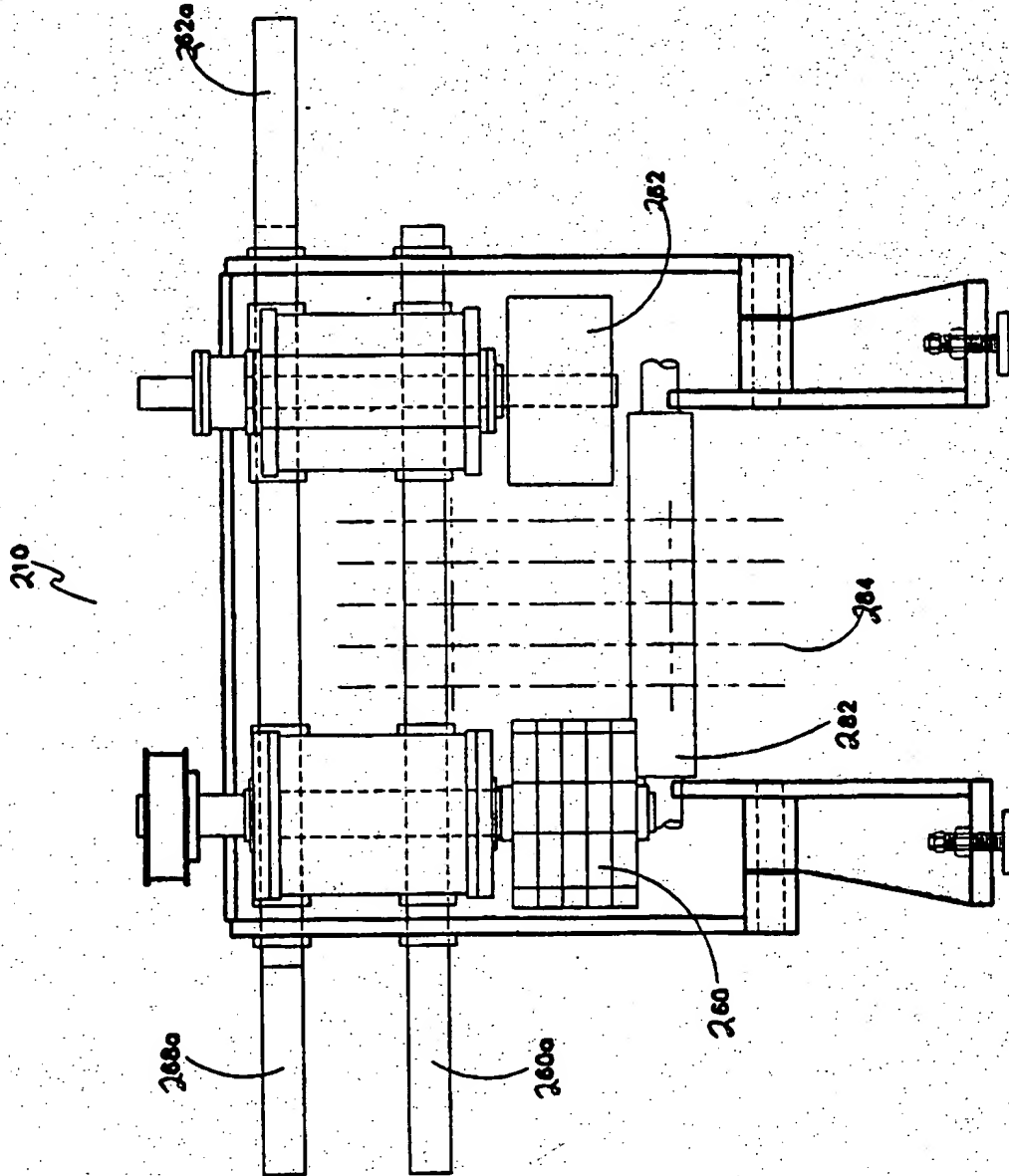
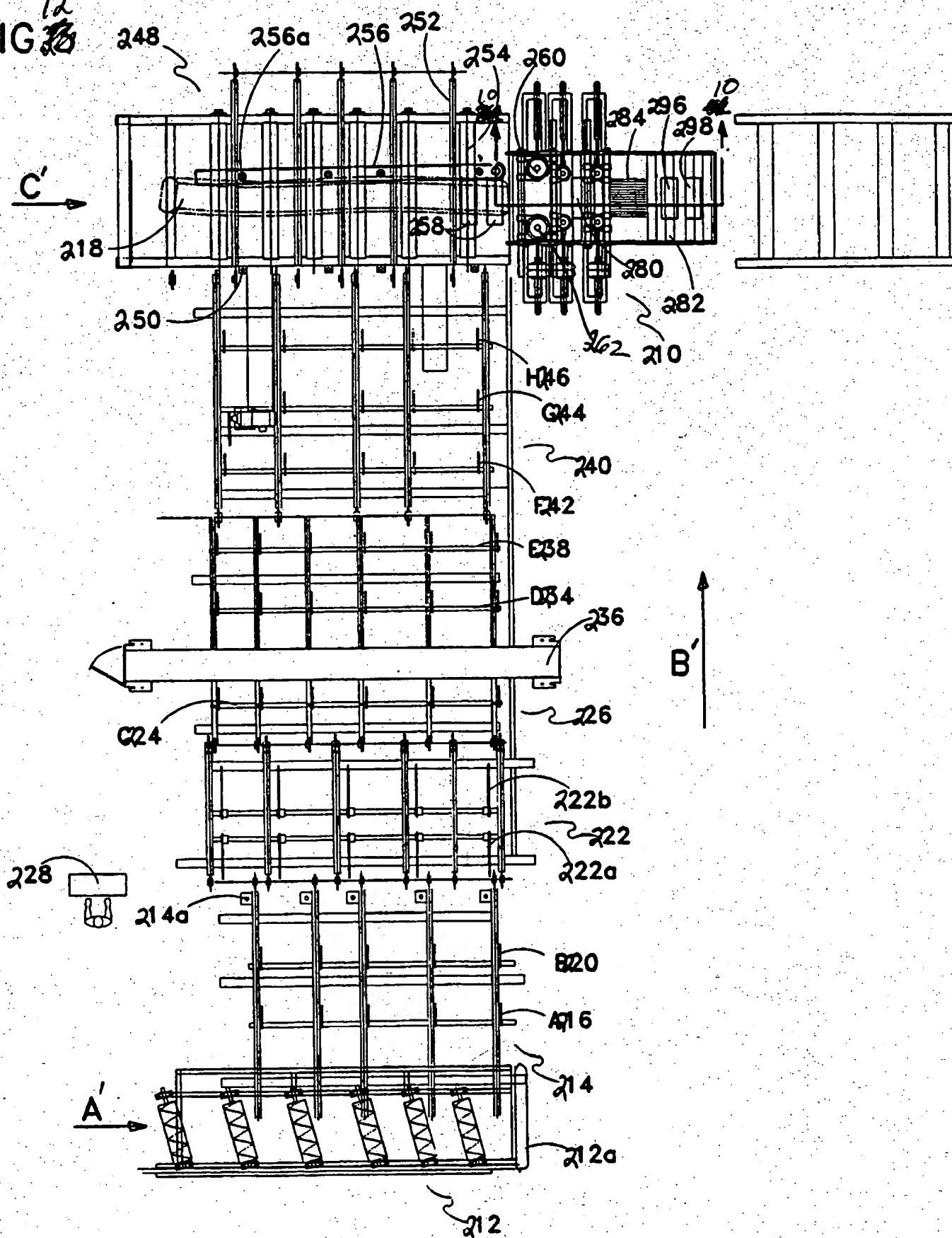


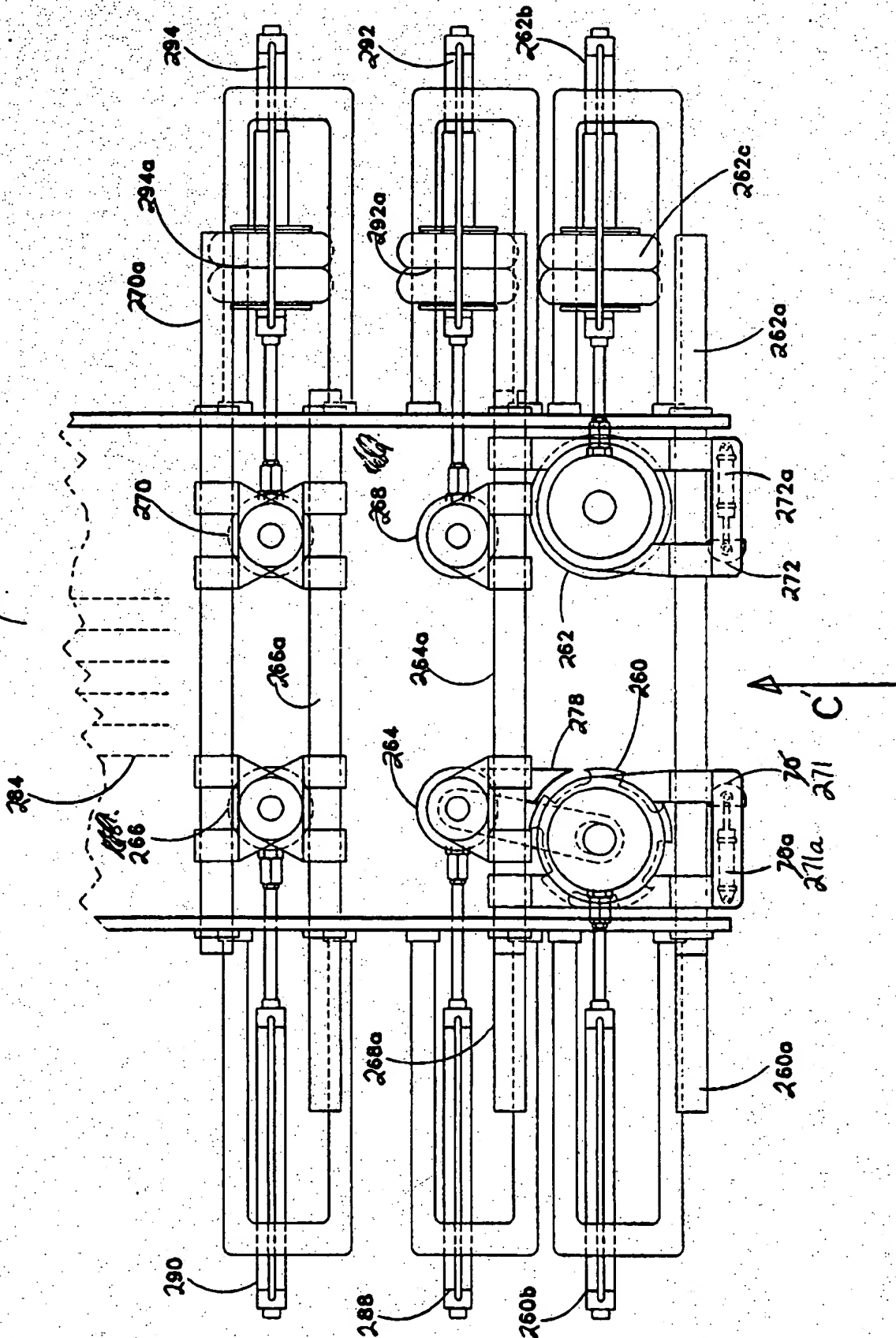
FIG 12



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FIG. 13

210



461250 44522880

FIG 11

210

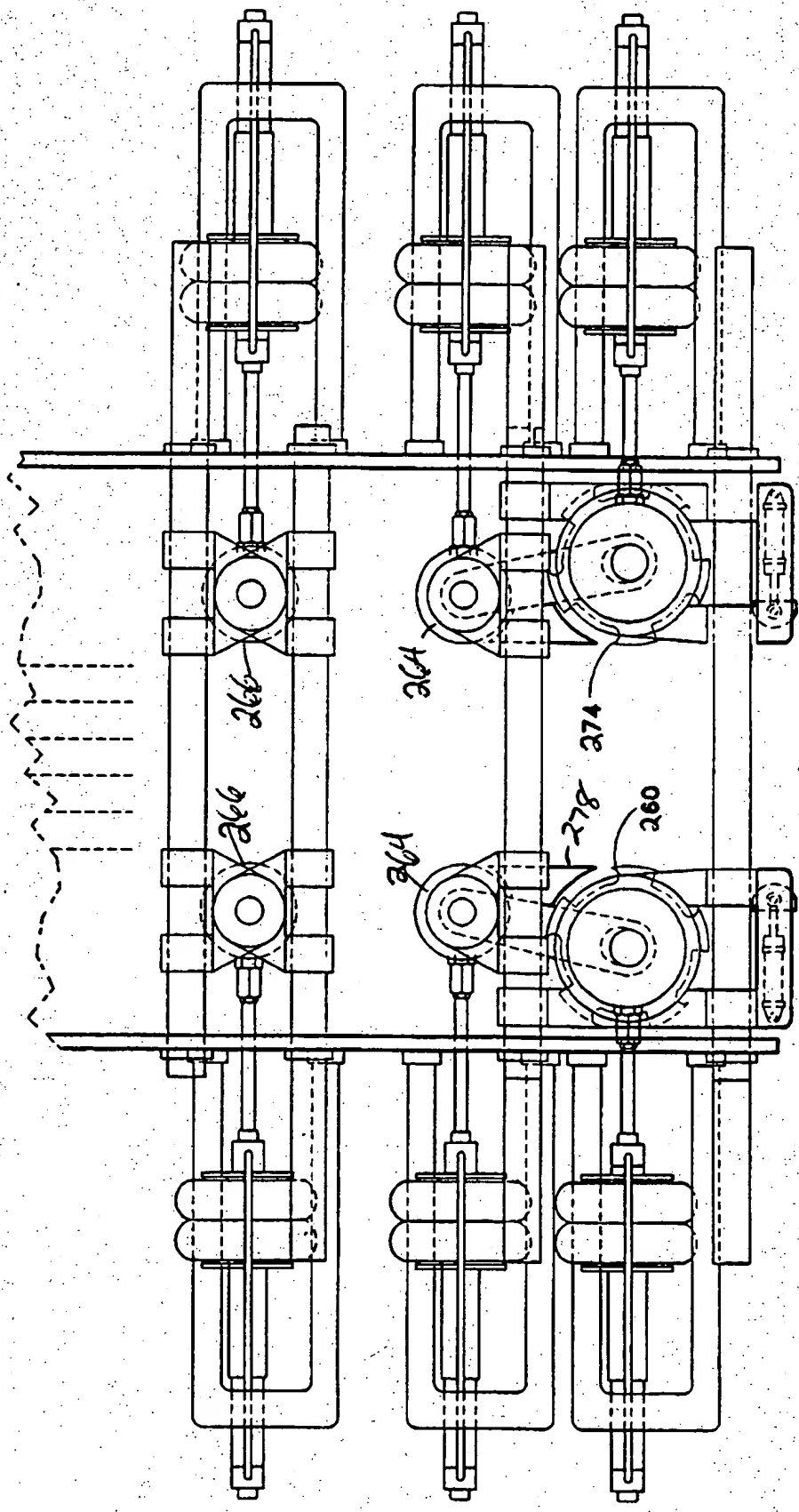
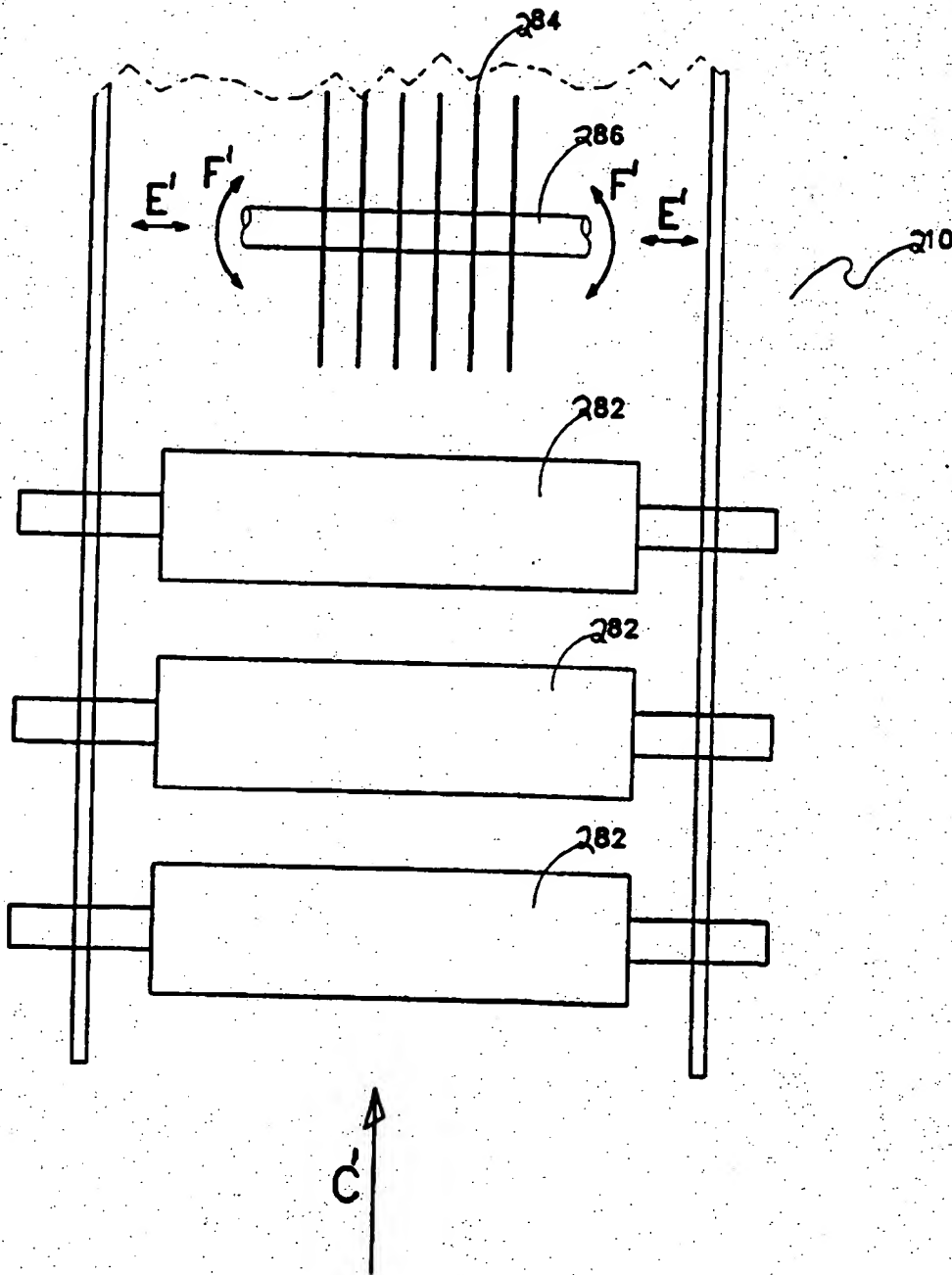




FIG. 15



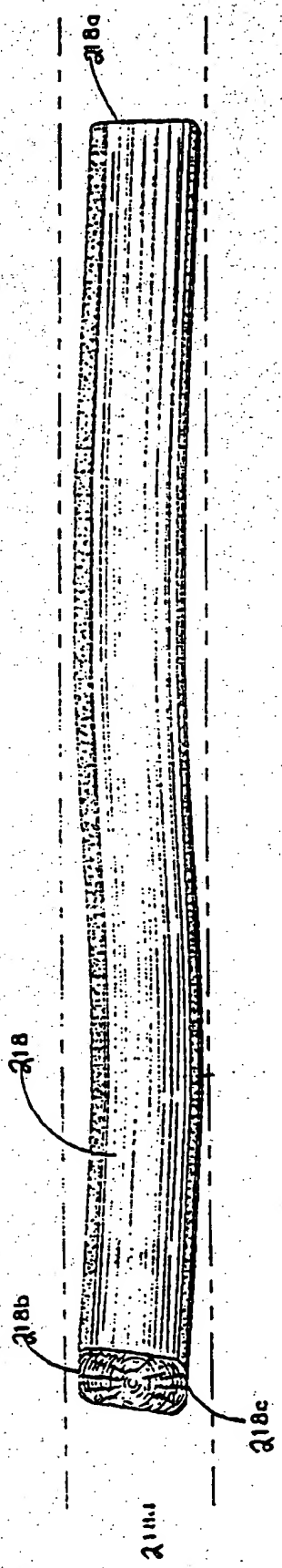
0822947-0349

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16  
FIG. 27



17a  
FIG. 27a



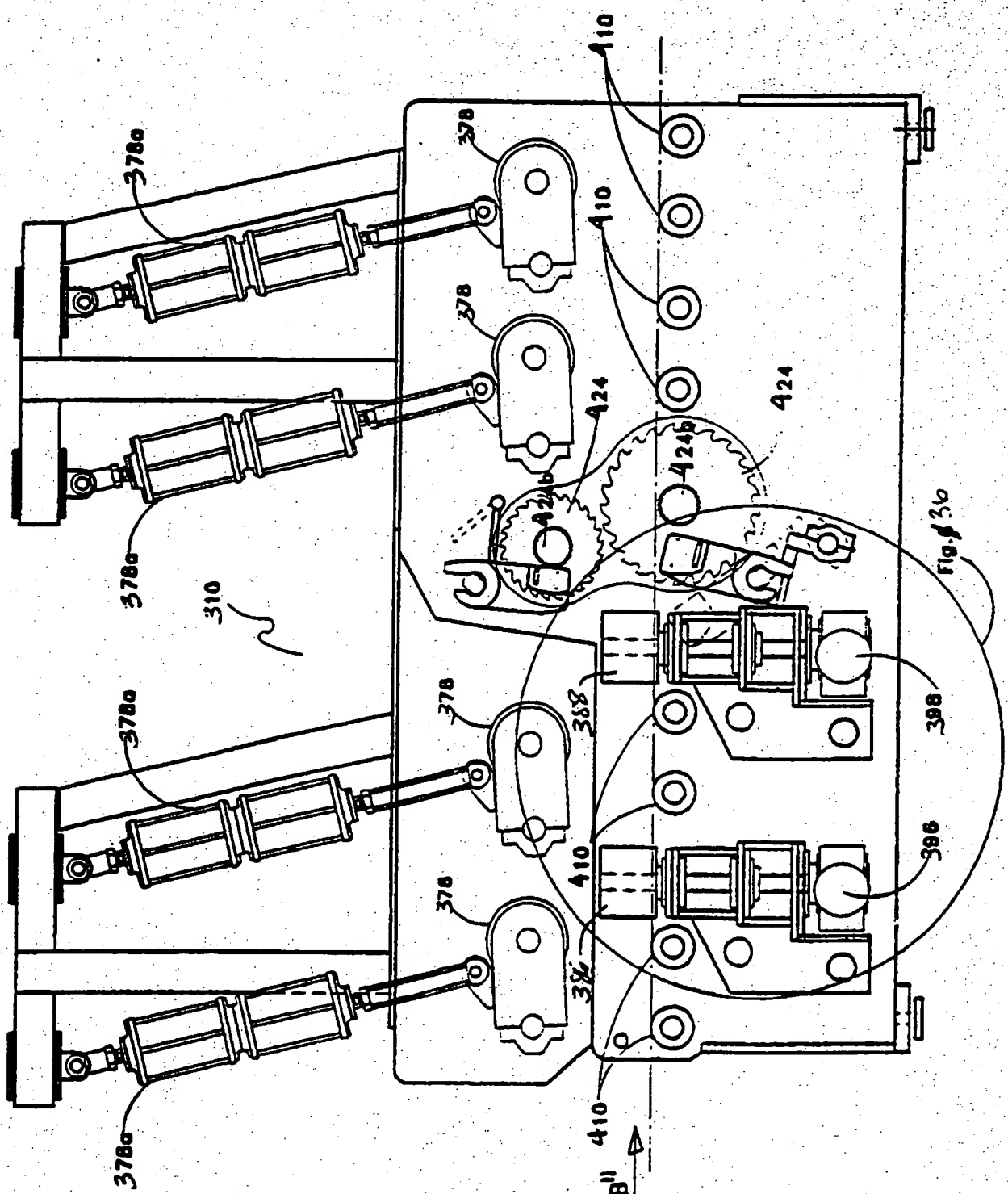


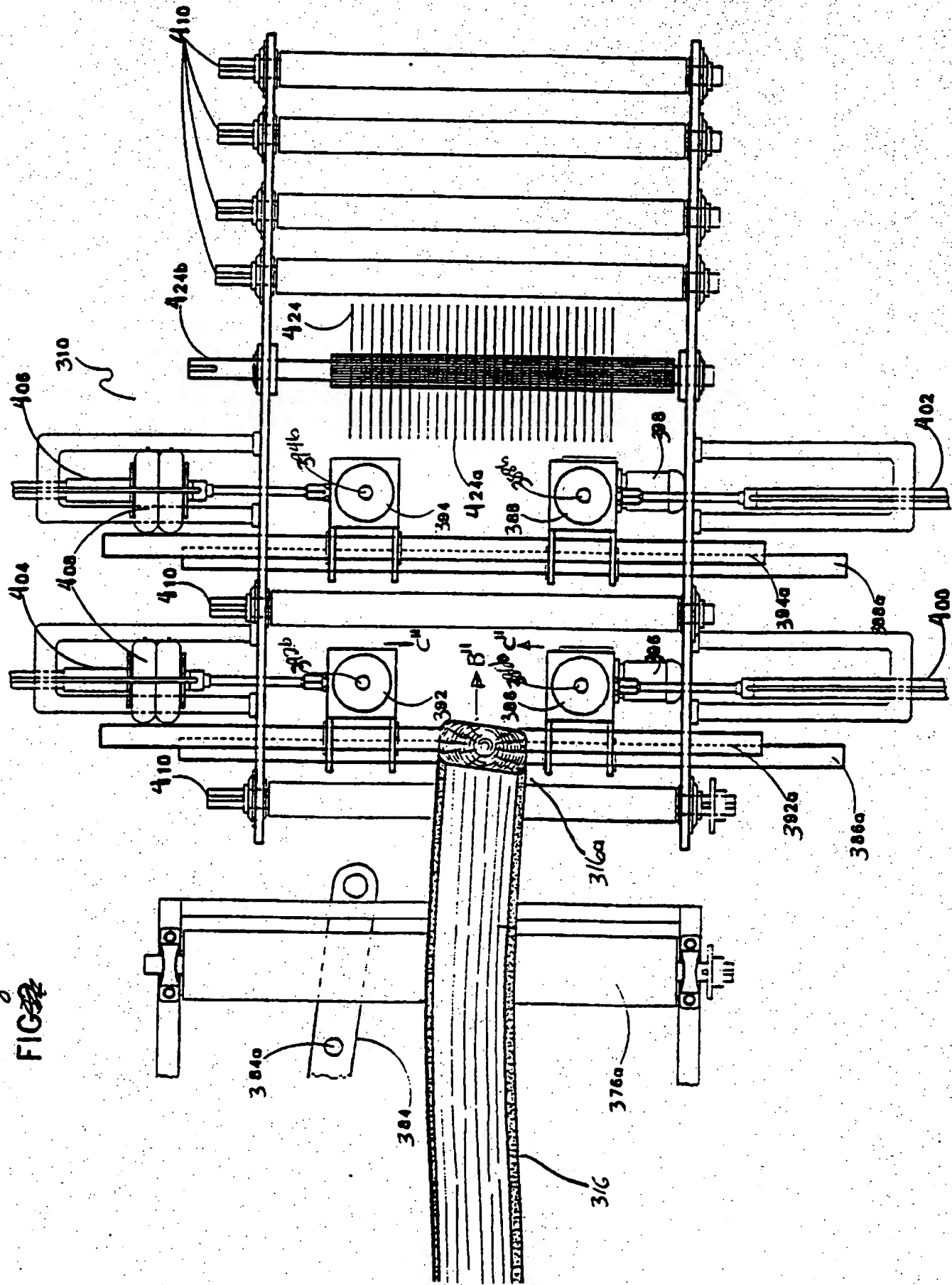
FIG 3

17

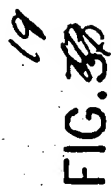
369

36

18  
FIG. 18



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FIG 20

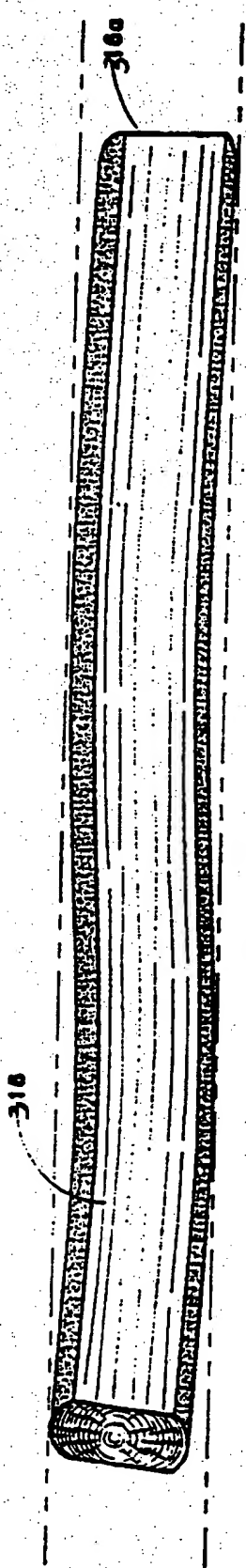
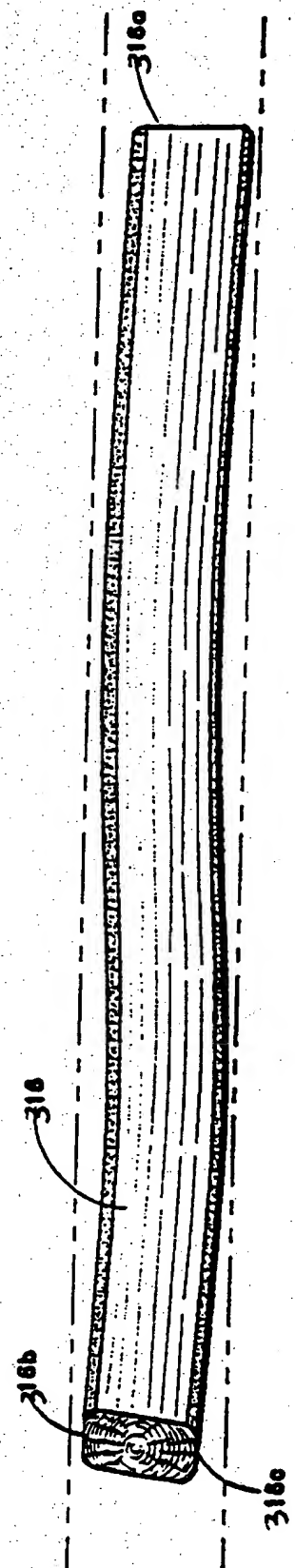


FIG 20a



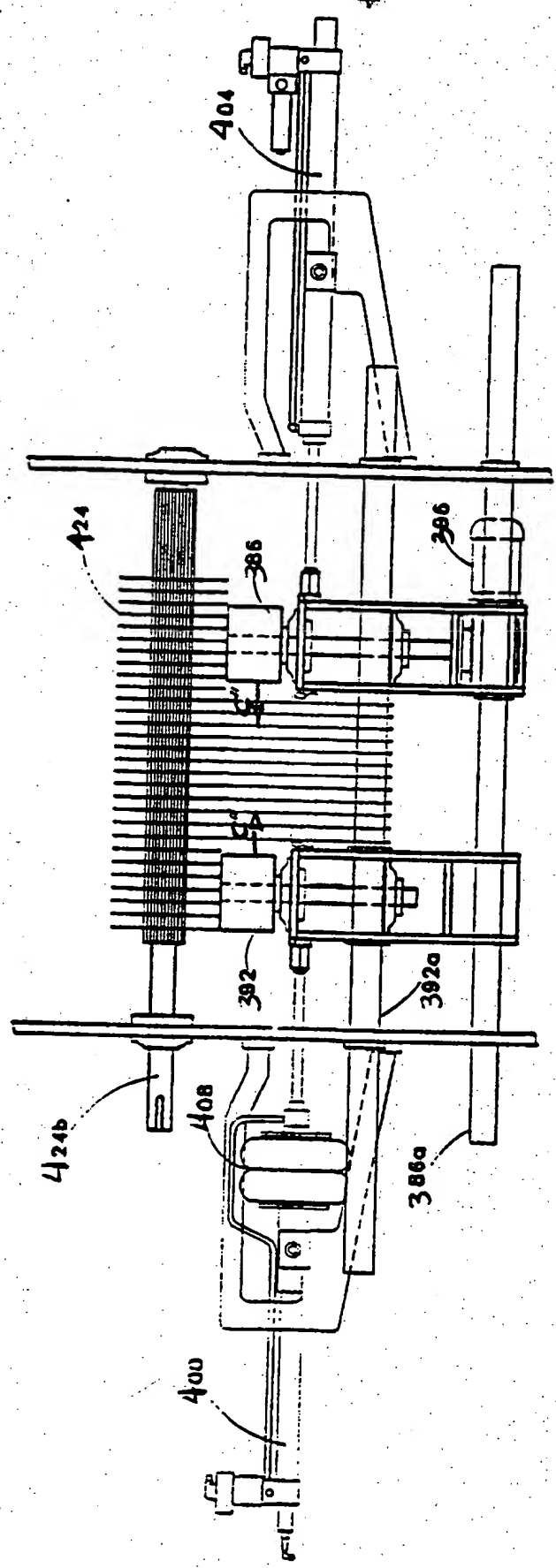
Received Time Mar. 21. 2:57PM  
Print Time Mar. 21. 3:23PM

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FIG 21

310



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FIG. 2

